

**IN THE CLAIMS:**

1. (Cancel)
2. (Currently Amended) A method as defined in claim ~~1~~ 8, wherein during the machining operation always those surface features which are computed for the current position of said hand instrument are superimposed over said video image, the current position of said hand instrument corresponding to a position of the implant within said cavity.
3. (Cancel)
4. (Currently Amended) A combination of a hand instrument, a display, and an evaluating unit for creating or excavating a cavity in a bone, in particular a bone cavity, which, wherein said hand instrument comprises a machining tool having a tip and a camera, wherein said hand instrument transmits ~~the~~ an image produced in said camera to said display, wherein a distance of between said camera ~~from the~~ and a tip of said machining tool is known, and wherein said evaluating unit computes surface features in the form of a ~~horizontal~~ horizon line and displays same on a display to enable proper control of the hand instrument as it creates or excavates a cavity in a bone to an end position wherein a computed horizon line of an adjacent tooth coincides with a visible camera-generated horizon line of said tooth.
5. (Previously Presented) A combination as defined in claim 4, wherein said camera has a depth of focus of from 5 to 30 mm and records a panorama view.

6. (Currently Amended) A combination as defined in claim 4, wherein said camera is integrated in the end of said hand instrument ~~which is near~~ said machining tool.

7. (Currently Amended) A combination as defined in claim 4, wherein including illuminating means ~~are provided for the purpose of illuminating~~ that part of the surface which is relevant for registering and displaying said horizon line.

8. (New) A method of moving a hand instrument which includes a machining tool and a camera located at a specific distance from the machining tool to provide cavity in a bone for a dental implant at a preparation site, comprising the following steps:

computing position-dependent surface features of a three-dimensional data set relating to a surface of an area at the preparation site relative to a desired position of the implant, the area in which the cavity is to be created being adjacent a tooth defining a horizon line and present in the form of a three-dimensional set of volume data;

detecting at least one section of the preparation site which exhibits a visible real surface feature by means of the camera on the hand instrument and a display providing a video image; and

superimposing a computed surface feature for a target position of said hand instrument such that altering the position and angle of said hand instrument causes a change in the position of said superimposed surface feature relative to the visible real surface feature, and moving the

hand instrument relative to the preparation site until the computed  
horizon line coincides with the horizon line of the adjacent tooth.